

Fig. 1
(Prior Art)

11B

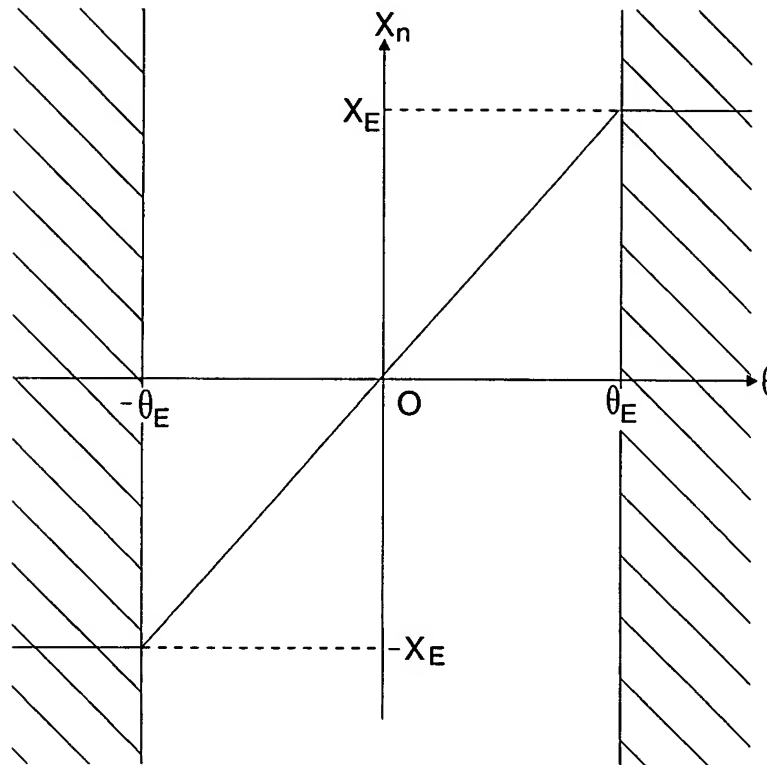


Fig. 2
(Prior Art)

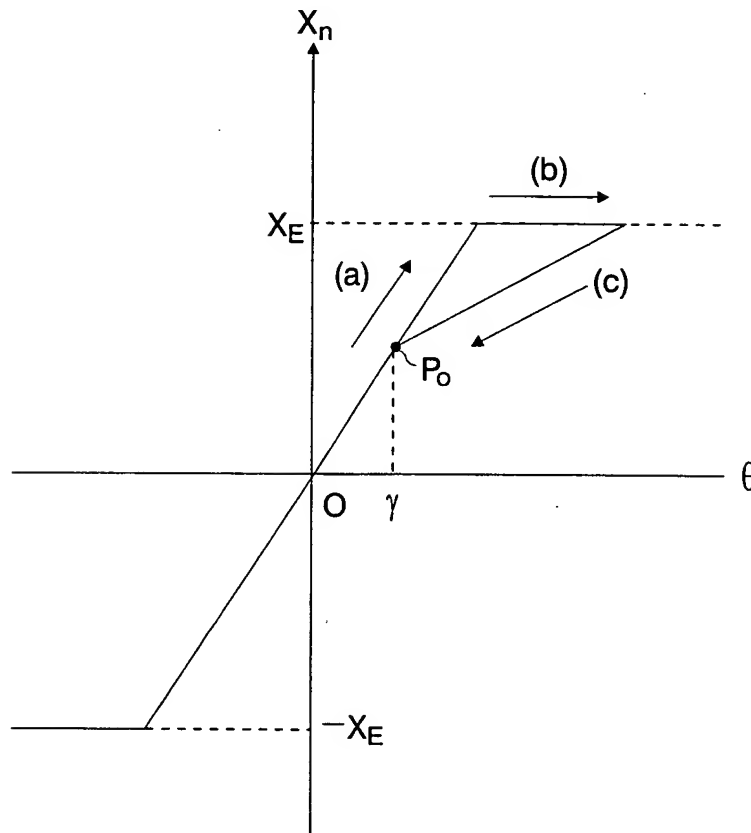


Fig. 3

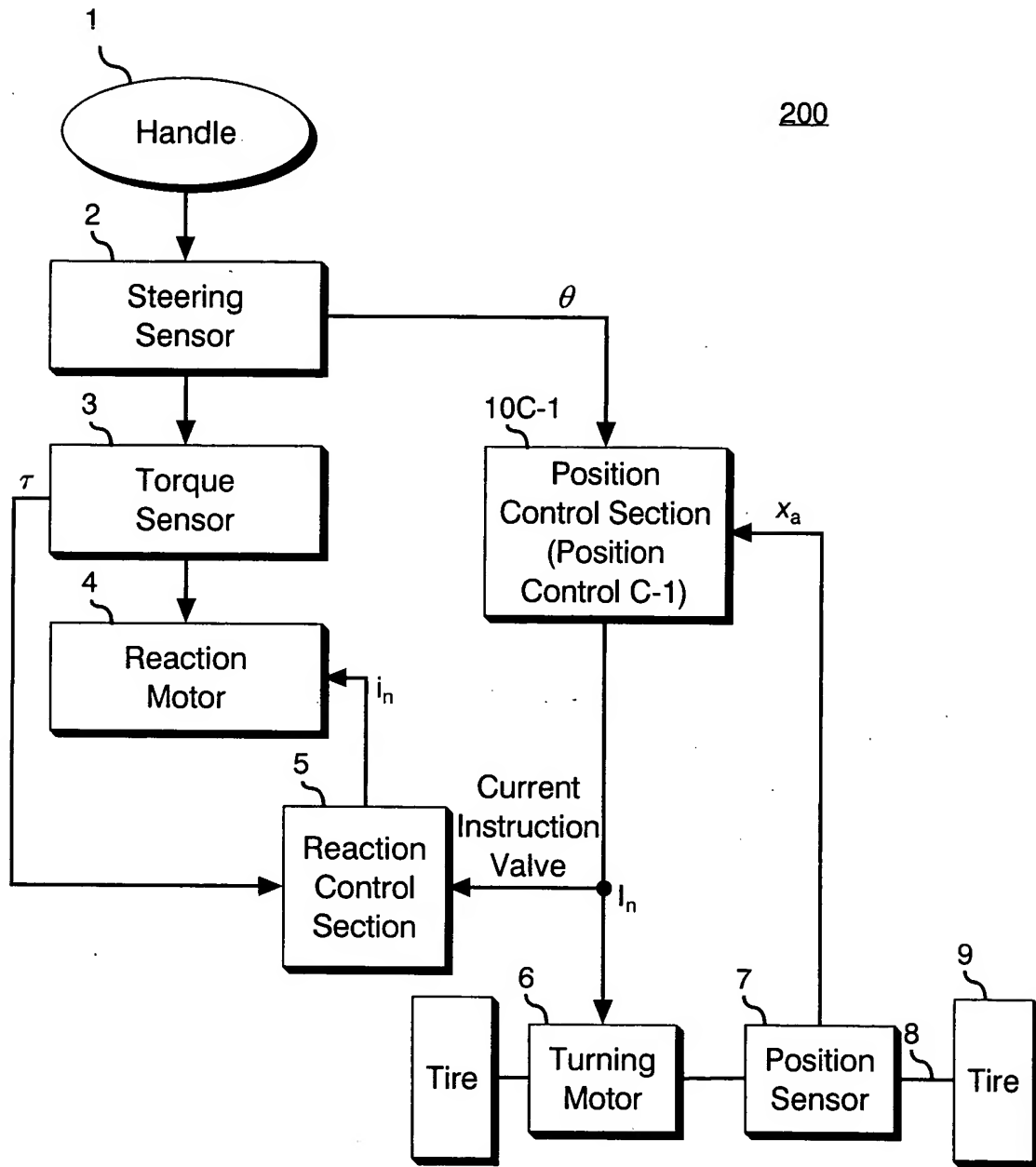
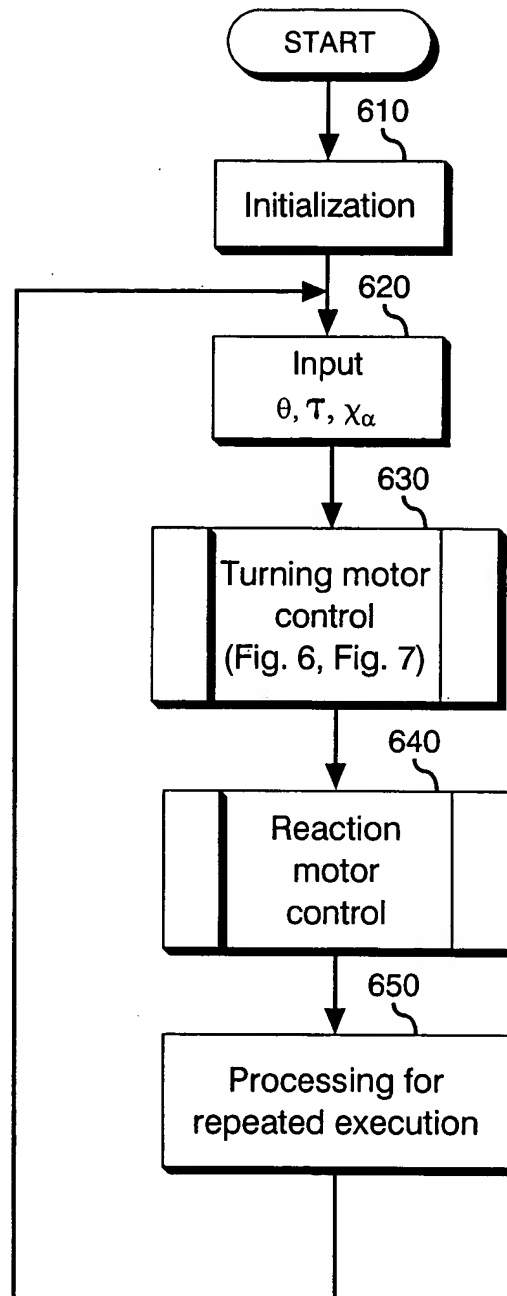


Fig. 4



Steering Control

Fig. 5

10C-1

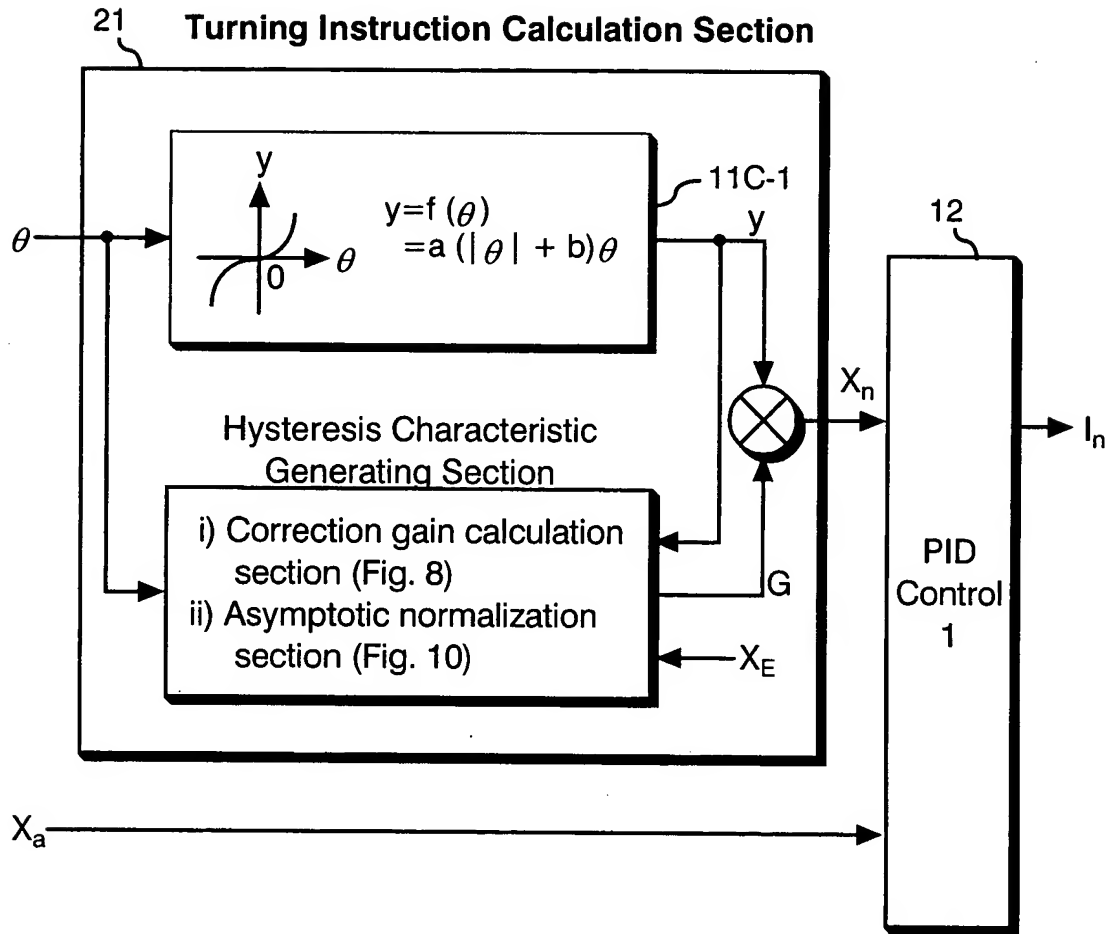
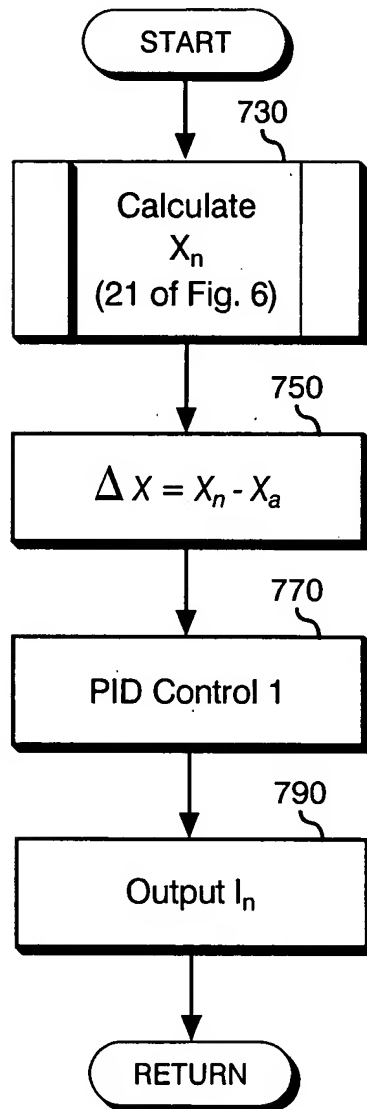
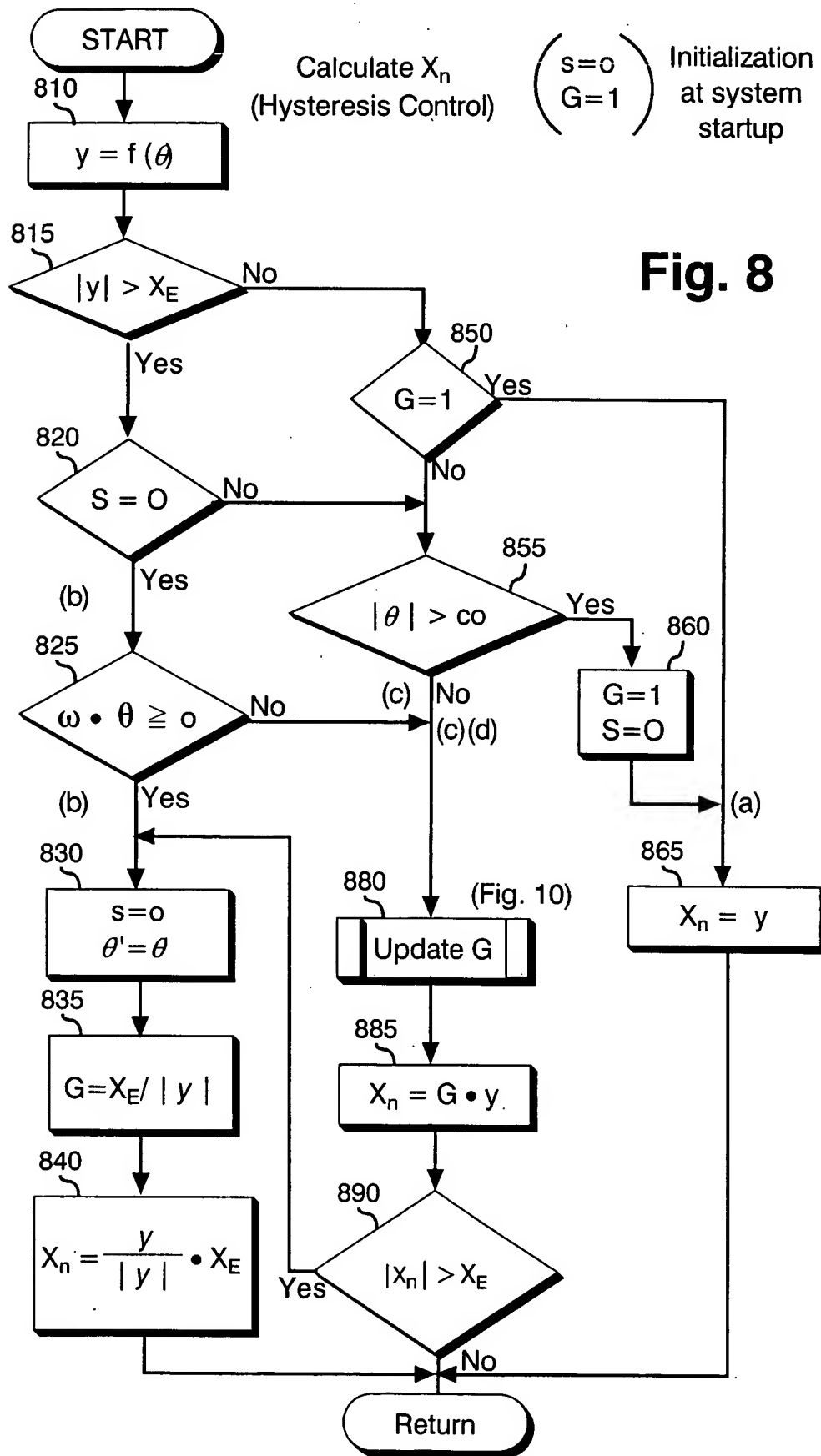


Fig. 6



Turning Motor Control

Fig. 7



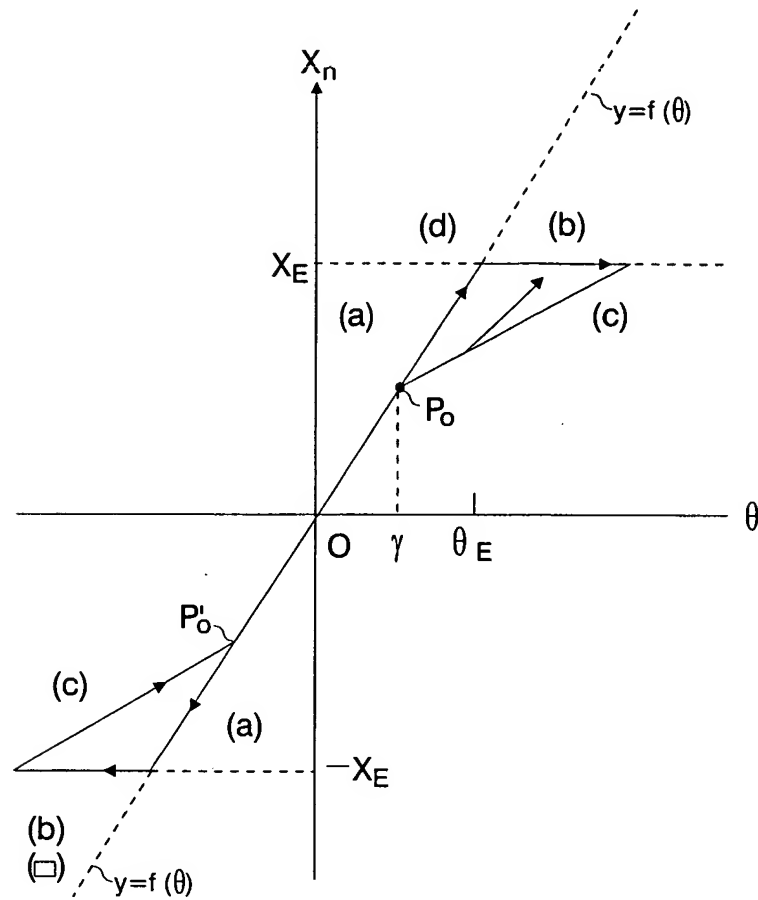
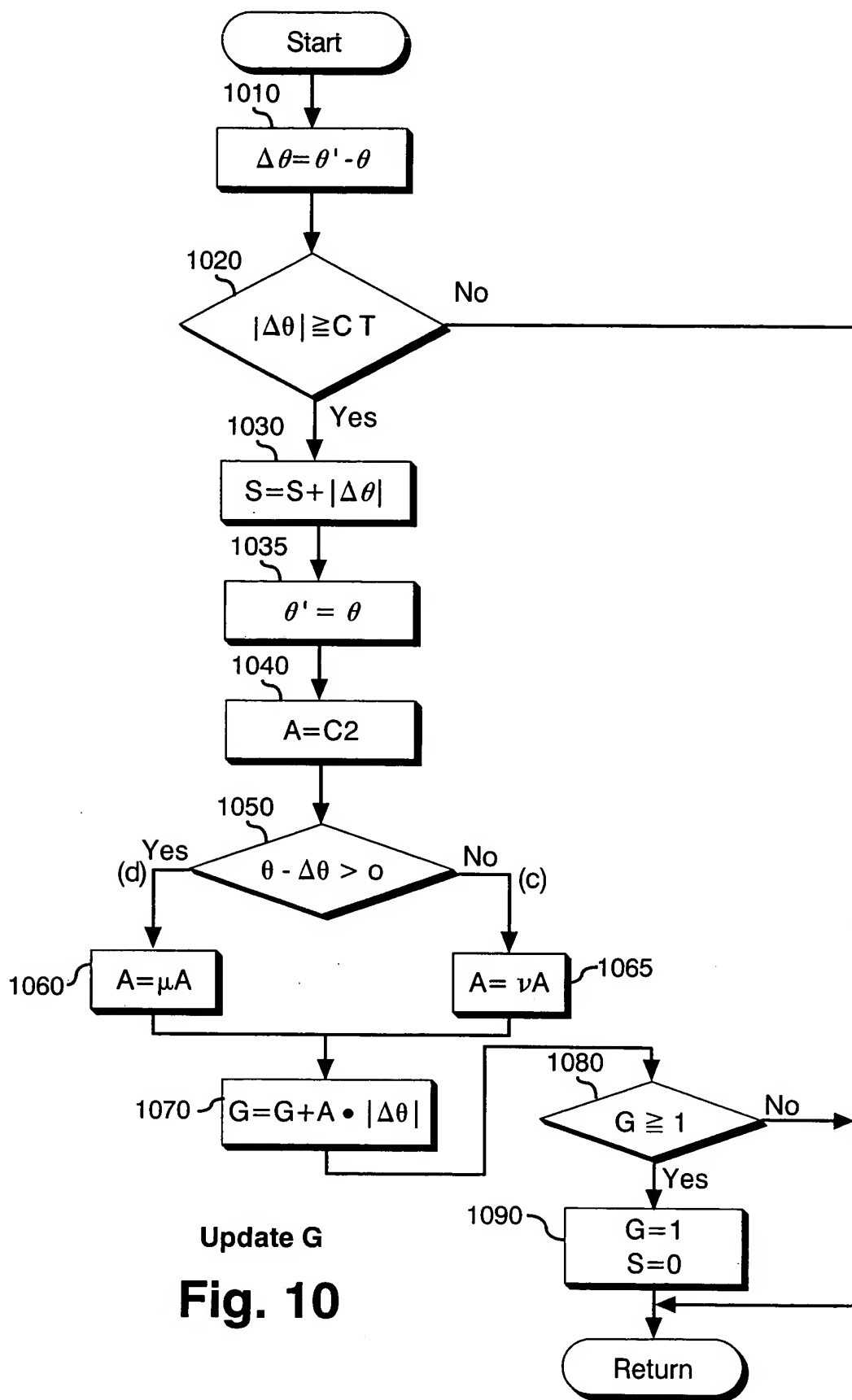


Fig. 9(a)

	$ y $	G	S	$\theta \cdot \Delta\theta$
(a)	$\geq X_E$	$=1$	$=0$	≤ 0
(b)	$> X_E$	<1	$=0$	≤ 0
(c)	$\leq X_E$	<1	>0	>0
(d)	$\leq X_E$	<1	>0	$\leq X_E$

$$(0 < G \leq 1, 0 \leq S)$$

Fig. 9(b)



Update G
Fig. 10

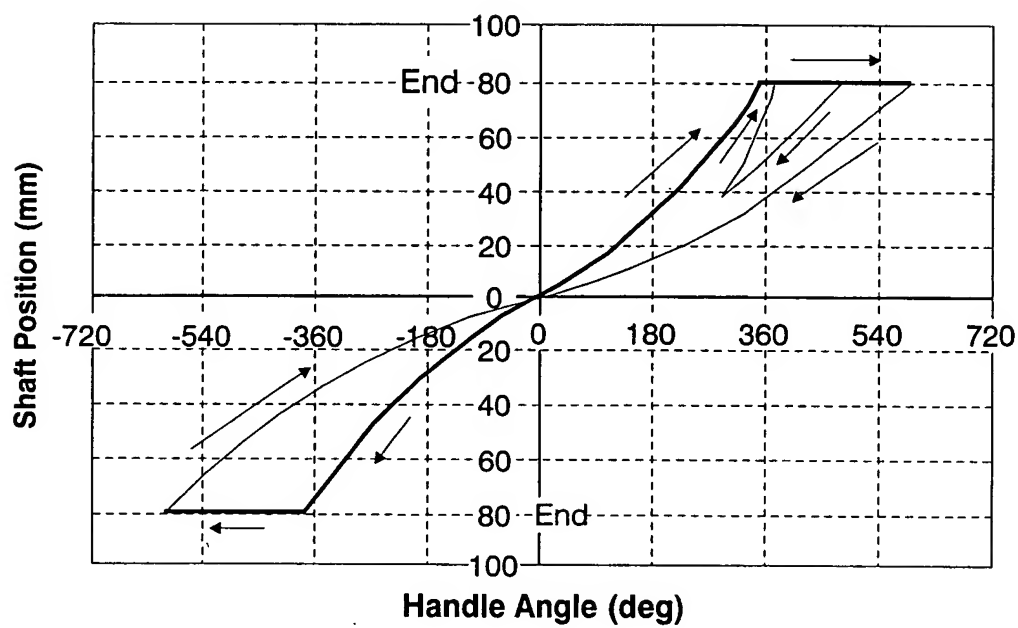


Fig. 11

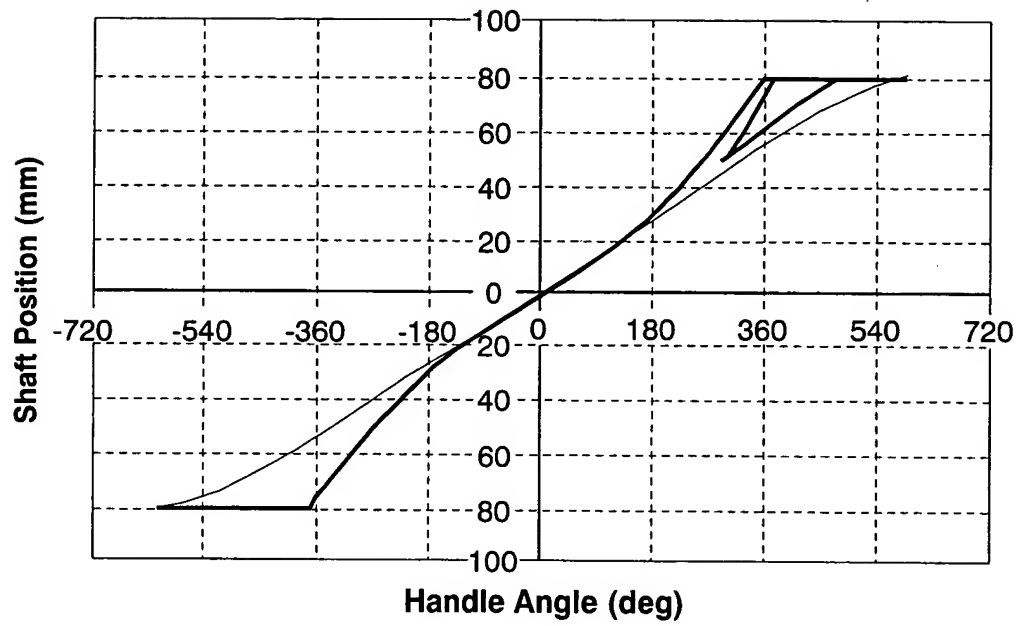


Fig. 12

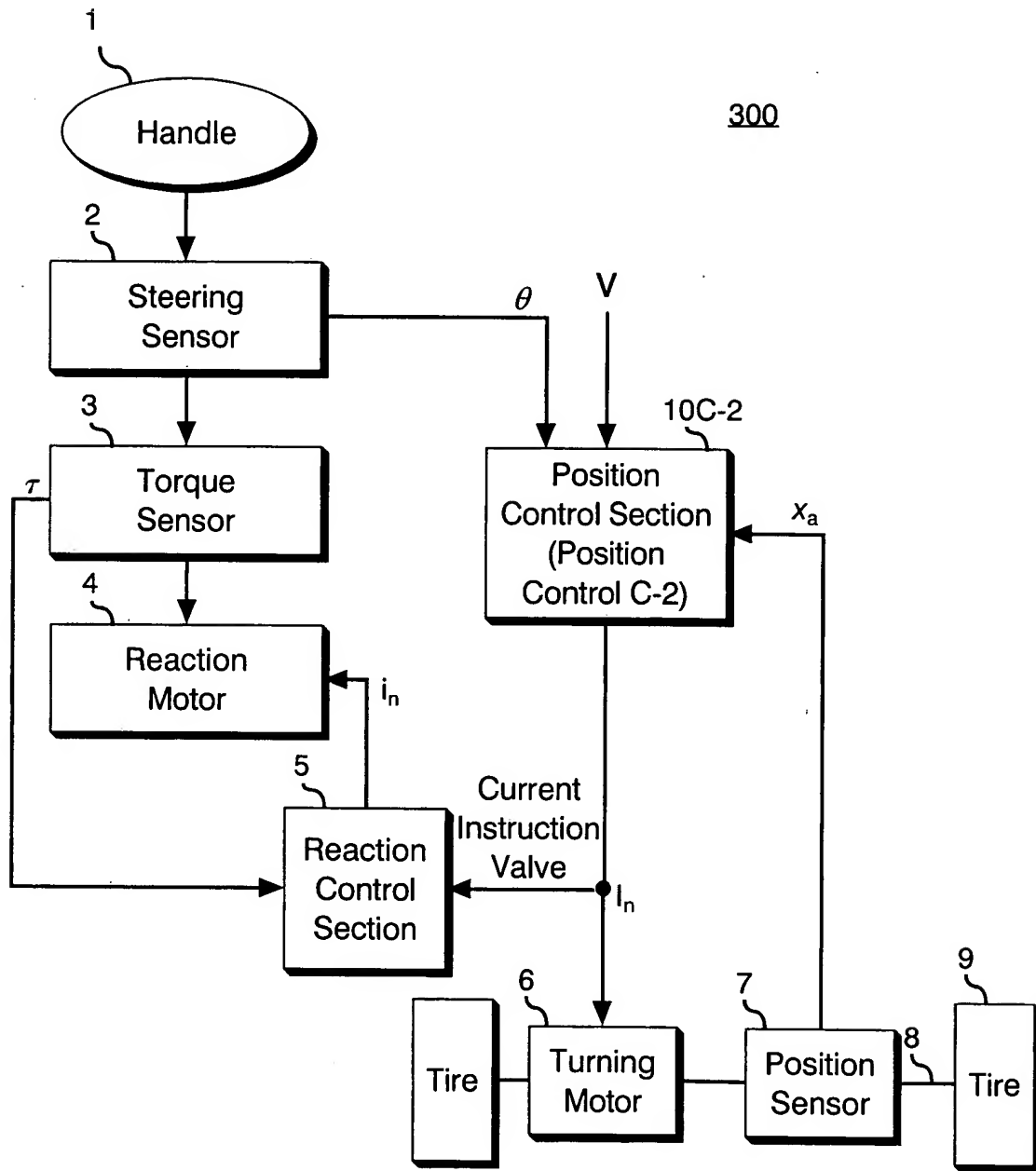


Fig. 13

10C-2

Turning Instruction Calculation Section (Fig. 8)

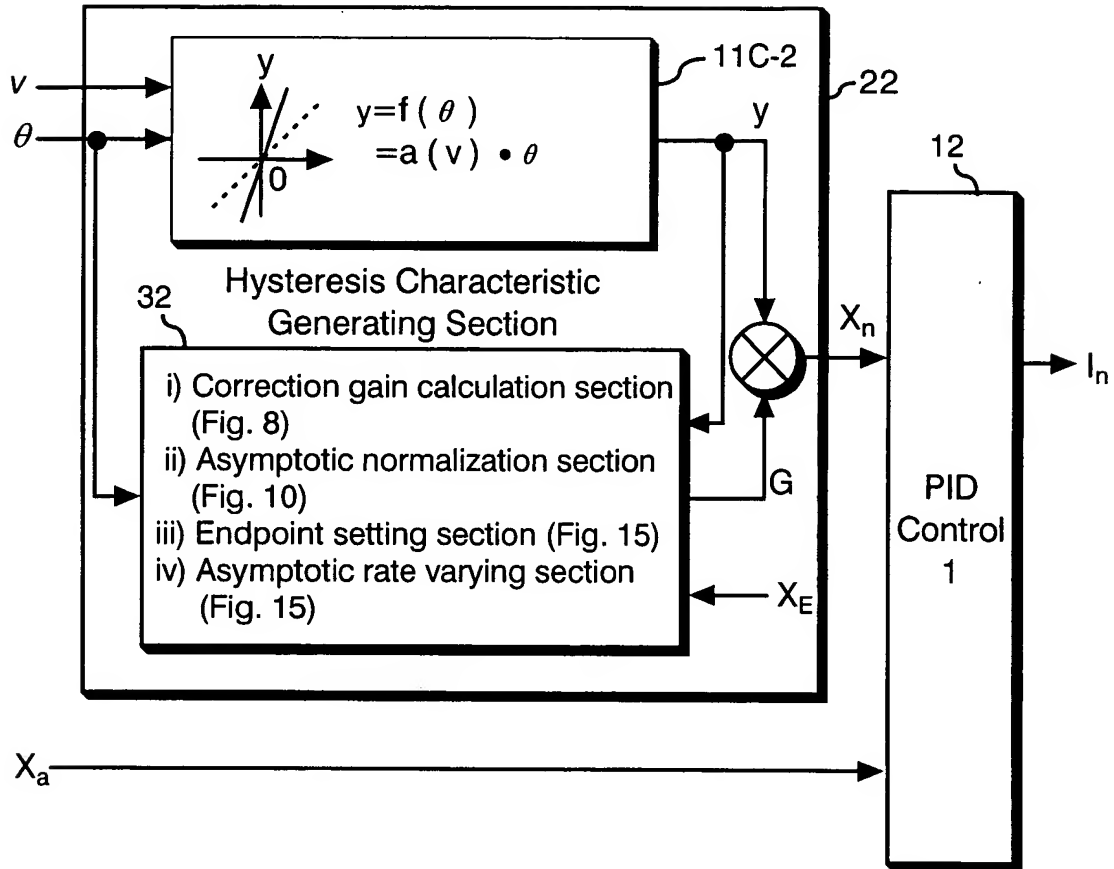


Fig. 14

Dynamic Updating of A
($\varepsilon > 0$)

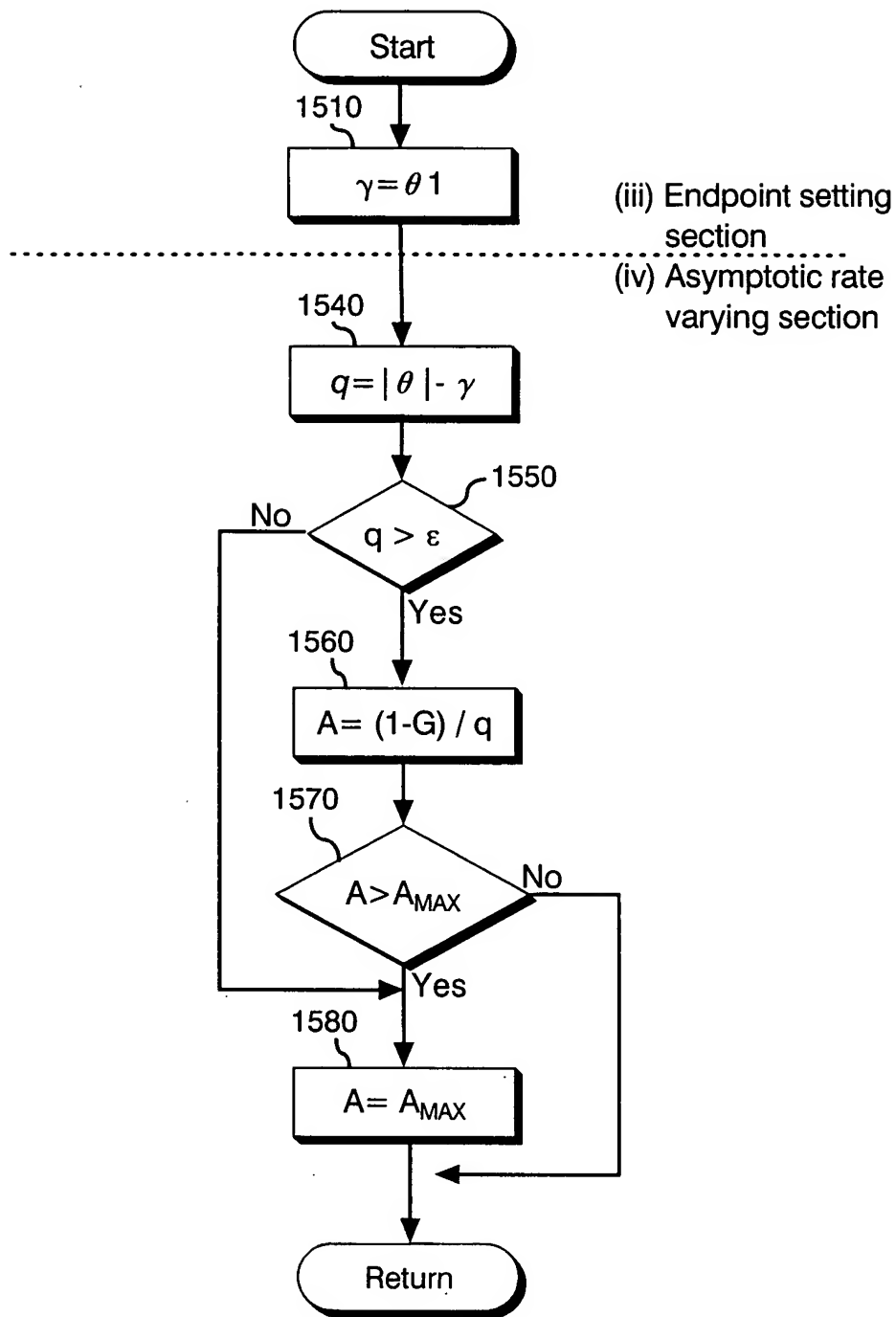


Fig. 15

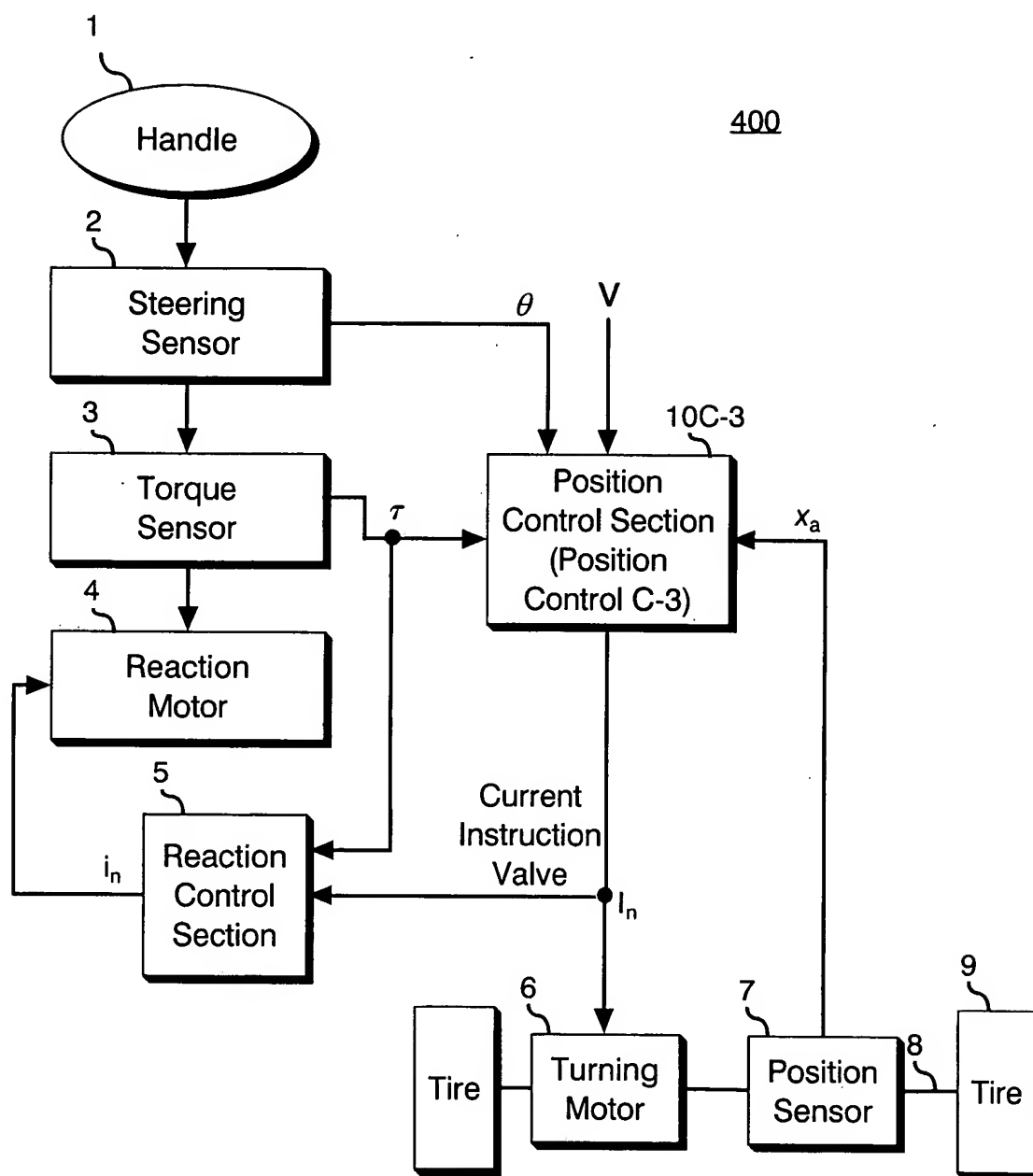


Fig. 16

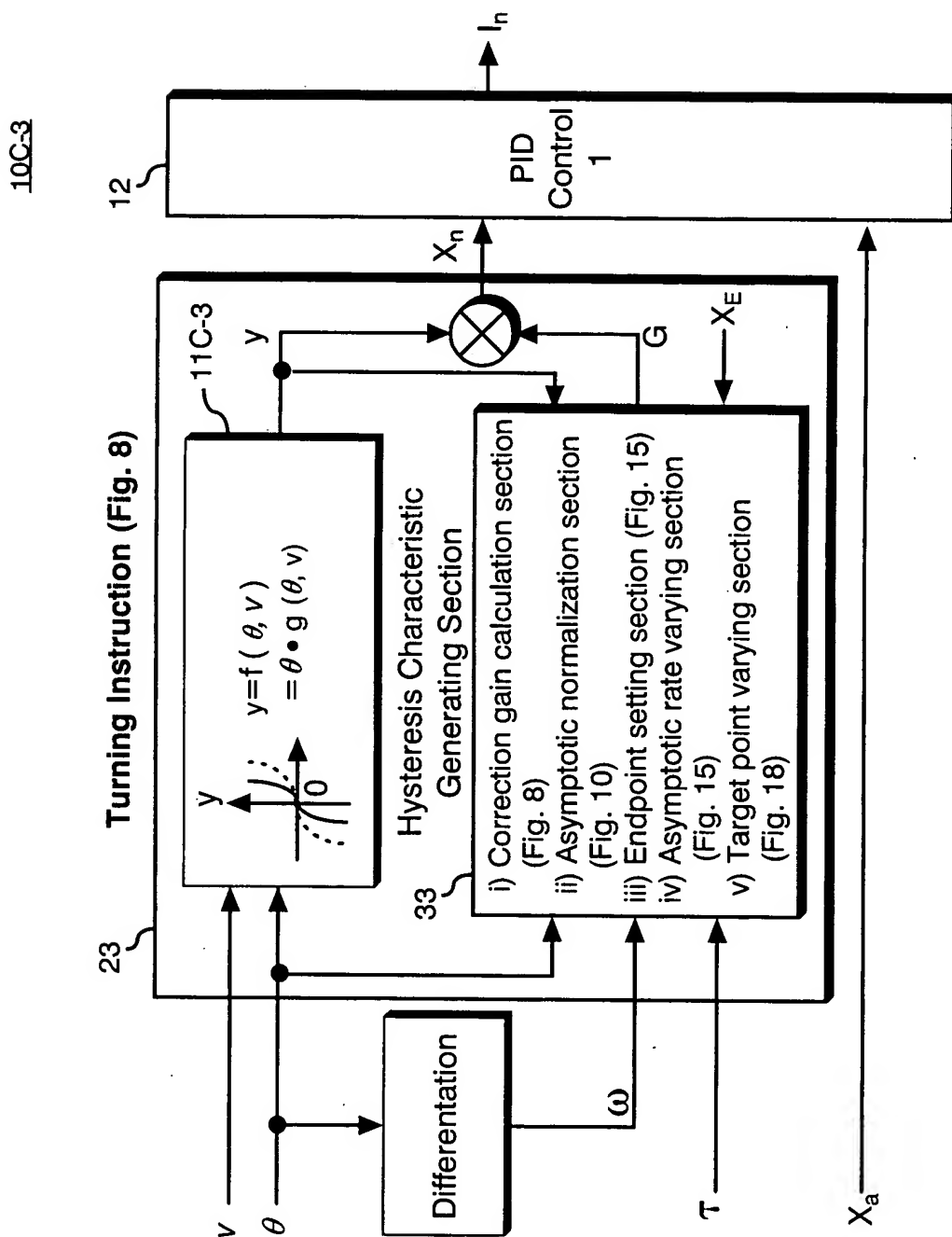
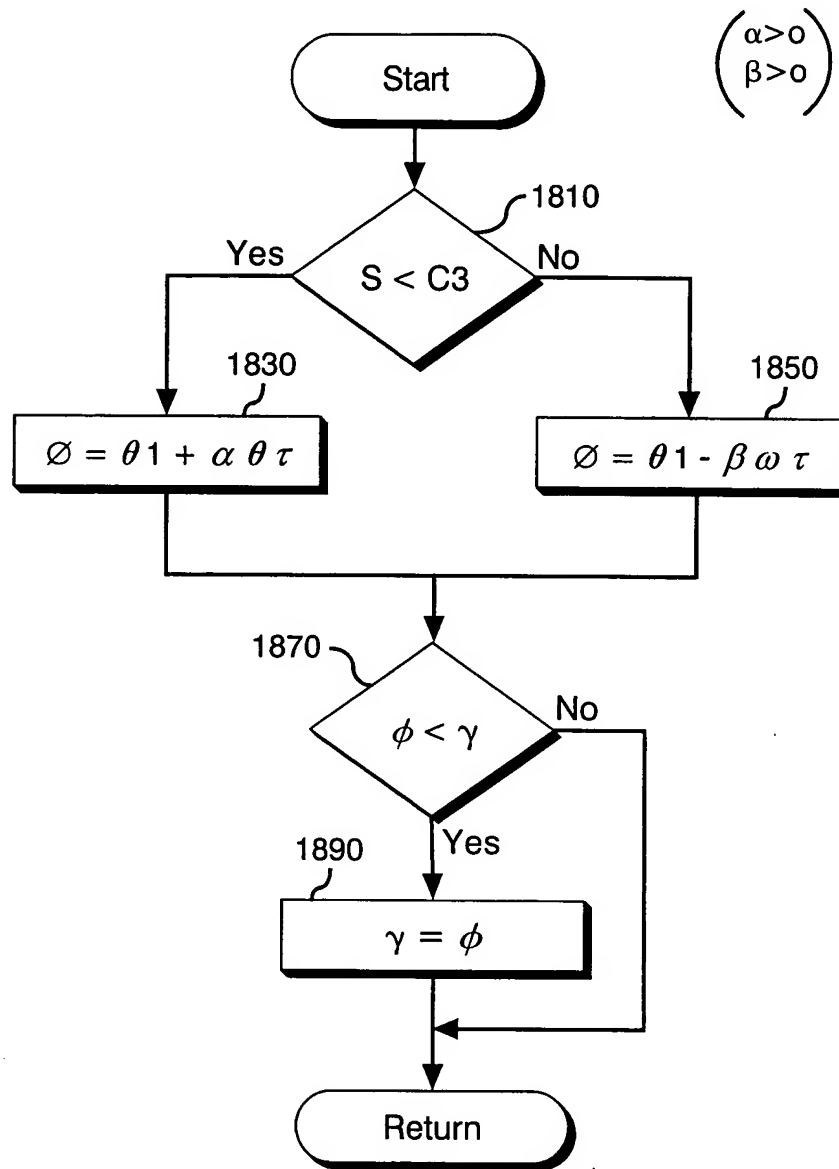


Fig. 17



Optimization of Target Coordinates

Fig. 18

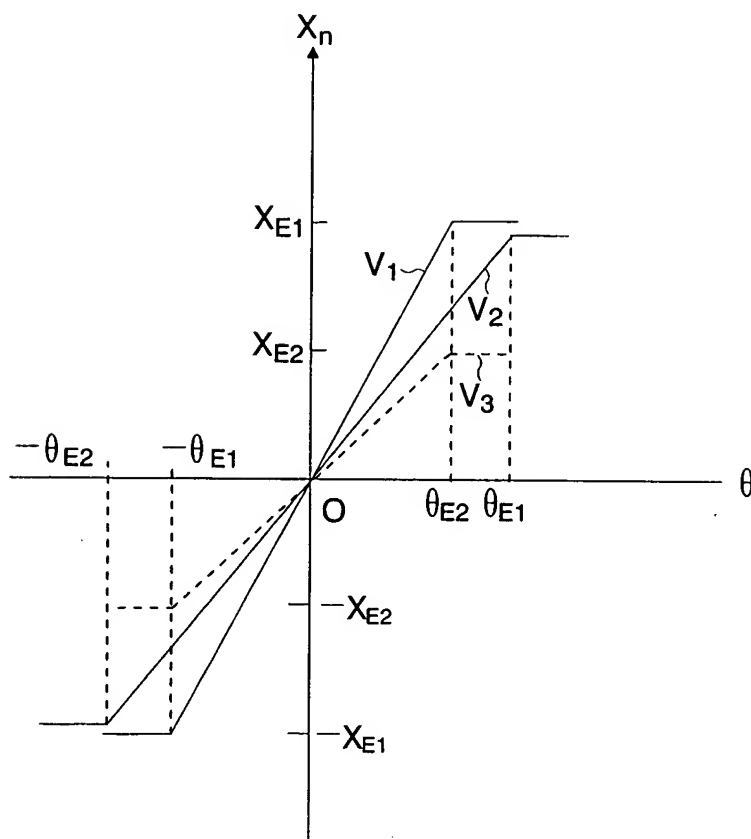


Fig. 19

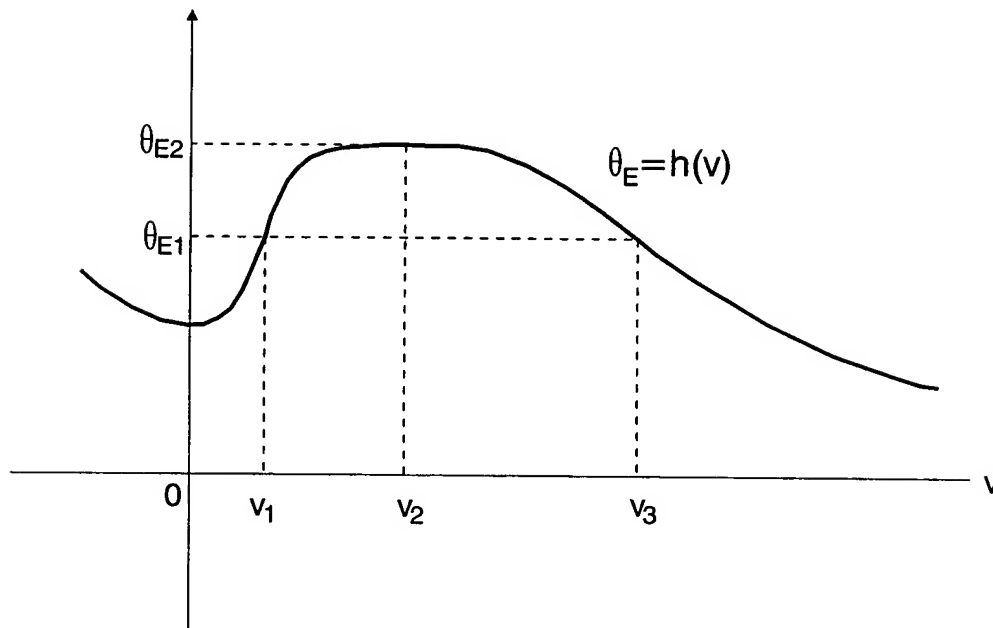


Fig. 20

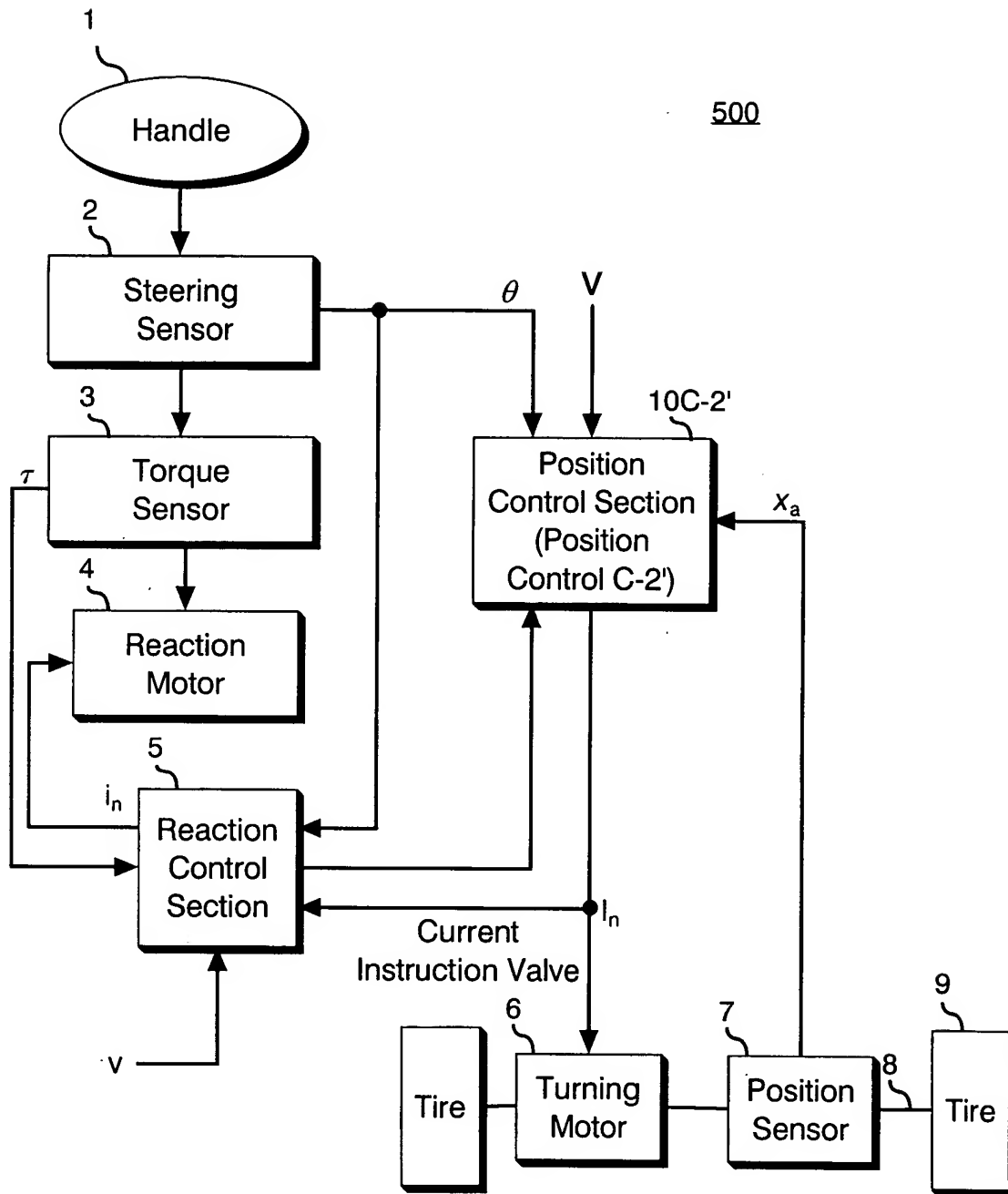


Fig. 21

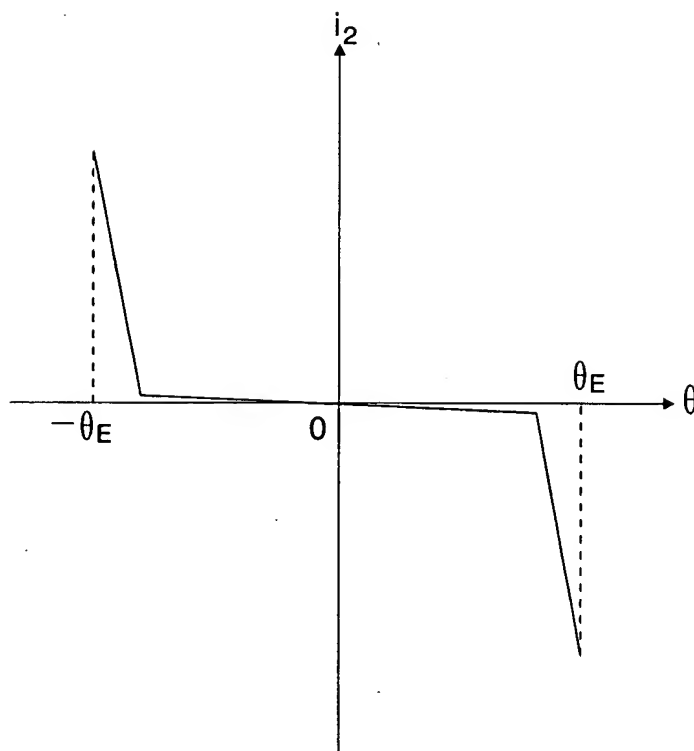
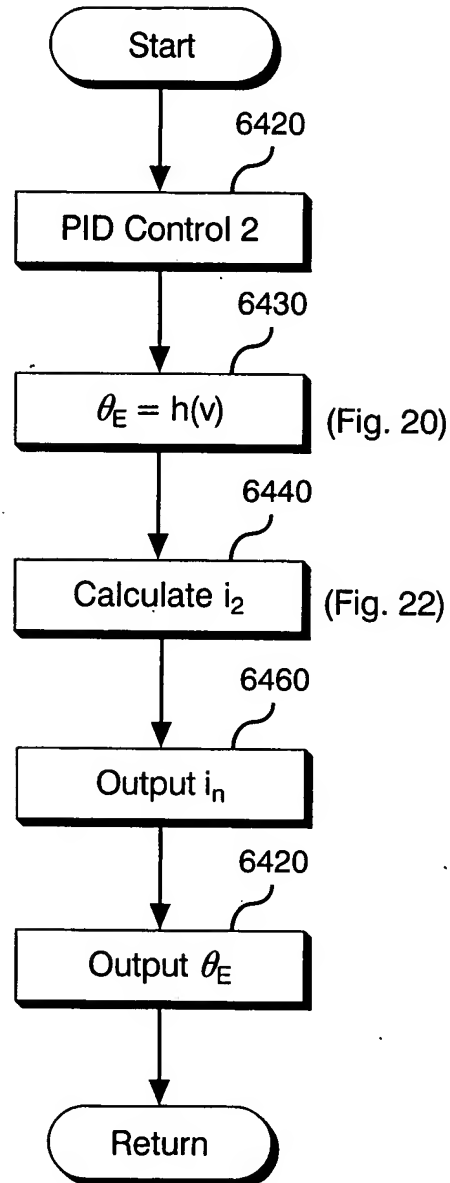


Fig. 22



Reaction Motor Control

Fig. 23

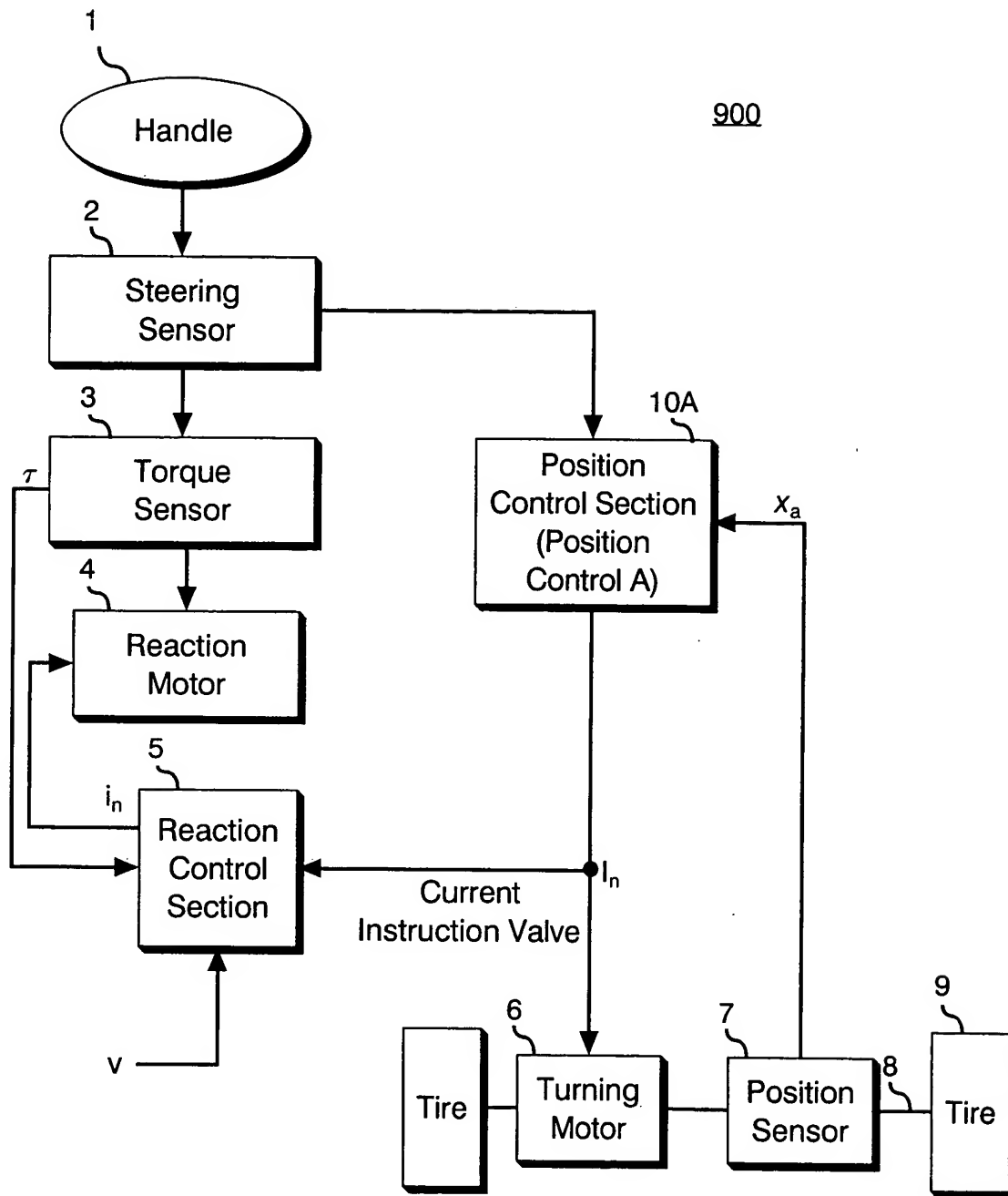


Fig. 24

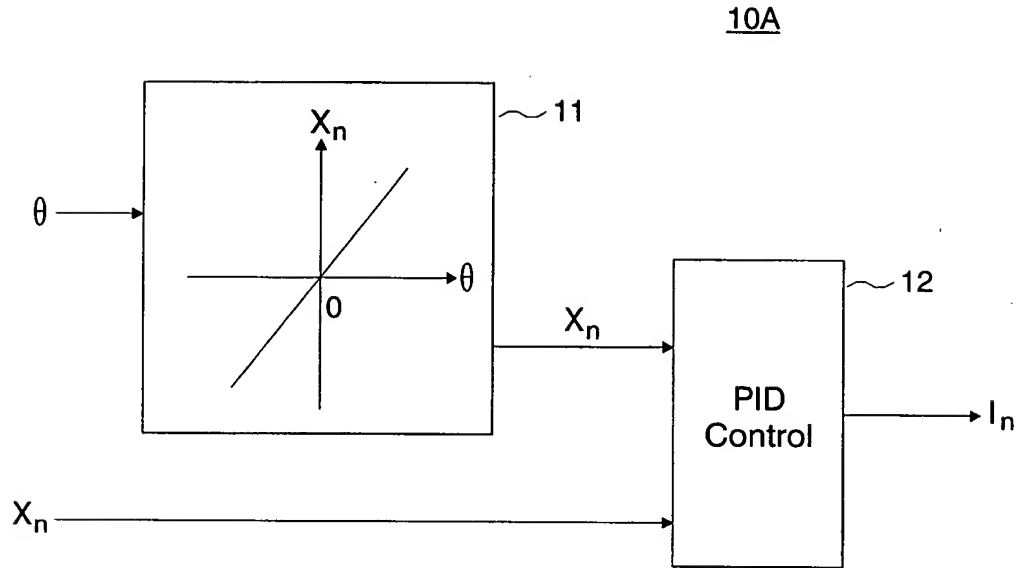


Fig. 25